IN THE CLAIMS

This listing of the claim will replace all prior versions and listings of claim in the present application.

Listing of Claims

Claims 1-14 (canceled).

15. (new) An object detecting method for detecting an object in an image obtained from an image pickup means, comprising:

a frame subtraction step of executing frame subtraction processing between an input image from the image pickup means and respective ones of a plurality of images each having a different time interval with respect to said input image;

a synthesizing step of adding together differential data obtained by said frame subtraction processing based on coefficients which are set for respective ones of predetermined regions of the image; and

an object detecting step of detecting an object based on data obtained from said synthesizing step.

16. (new) An object detecting method according to claim 15, wherein said coefficients are set based on a distance from the image pickup means.

17. (new) An object detecting method according to claim 15, wherein said coefficients are set based on a magnitude of movement of an object in a respective one of predetermined regions of said image.

18. (new) An object detecting method for detecting an object in an image obtained from an image pickup means, comprising:

a frame subtraction step of executing frame subtraction processing for each one of predetermined regions of an image with a frame time interval being changed for each region; and

an object detecting step of detecting an object based on differential data obtained from said frame subtraction processing.

19. (new) An object detecting method according to claim 18, wherein said frame time interval is set based on a distance from said image pickup means.

20. (new) An object detecting method according to claim 18, wherein said frame time interval is set based on a magnitude of movement of an object tin respective one of predetermined regions of said image.

21. (new) An object detecting apparatus for detecting an object in an image obtained from image pickup means, comprising:

frame subtraction means for executing frame subtraction processing between an input image from the image pickup means and respective ones of a plurality of images each having a different time interval with respect to said input image;

synthesizing means for adding together differential data obtained by said frame subtraction processing based on coefficients which are set for respective ones of predetermined regions of the image; and

object detecting means for detecting an object based on data obtained from said synthesizing means.

22. (new) An object detecting apparatus according to claim 21, wherein said coefficients are set based on a distance from said image pickup means.

23. (new) An object detecting apparatus according to claim 7, wherein said coefficients are set based on a magnitude of movement of an object in respective one of predetermined regions of said image.

24. (new) An object detecting apparatus for detecting an object in an image obtained from an image pickup means, comprising:

frame subtraction means for executing frame subtraction processing for each one of predetermined regions of an image with a frame time interval being changed for each region; and

object detecting means for detecting an object based on differential data obtained from said frame subtraction means.

25. (new) An object detecting apparatus according to claim 23, wherein said frame time interval is set based on a distance from said image pickup means.

26. (new) An object detecting apparatus according to claim 23, wherein said frame time interval is set based on a magnitude of movement of an object in a respective one of predetermined regions of said image.